IE 410 – INTRODUCTION TO ROBOTICS

Lab-2 report

Team M410:

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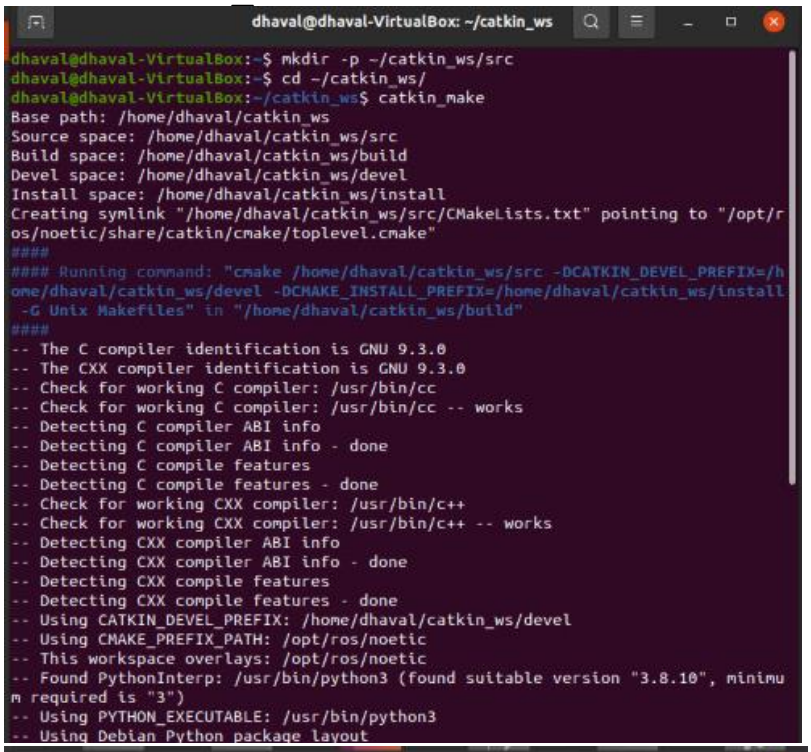
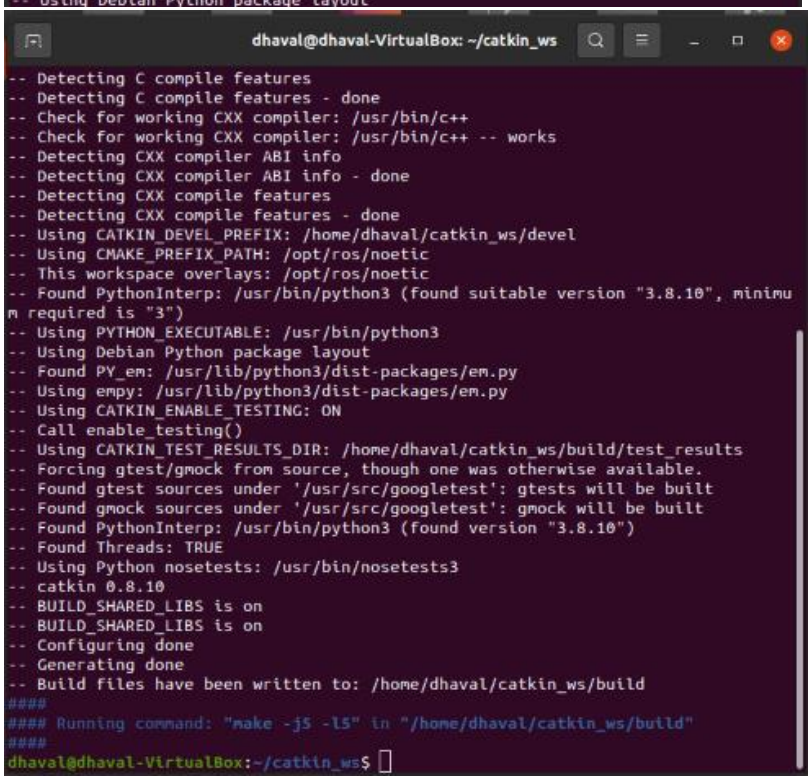
- In this lab, we will use ROS and python to use Turtlesim.
- We will use following commands for turtlesim.
- Creating ROS workspace
  Commands to create and build a catkin workspace:

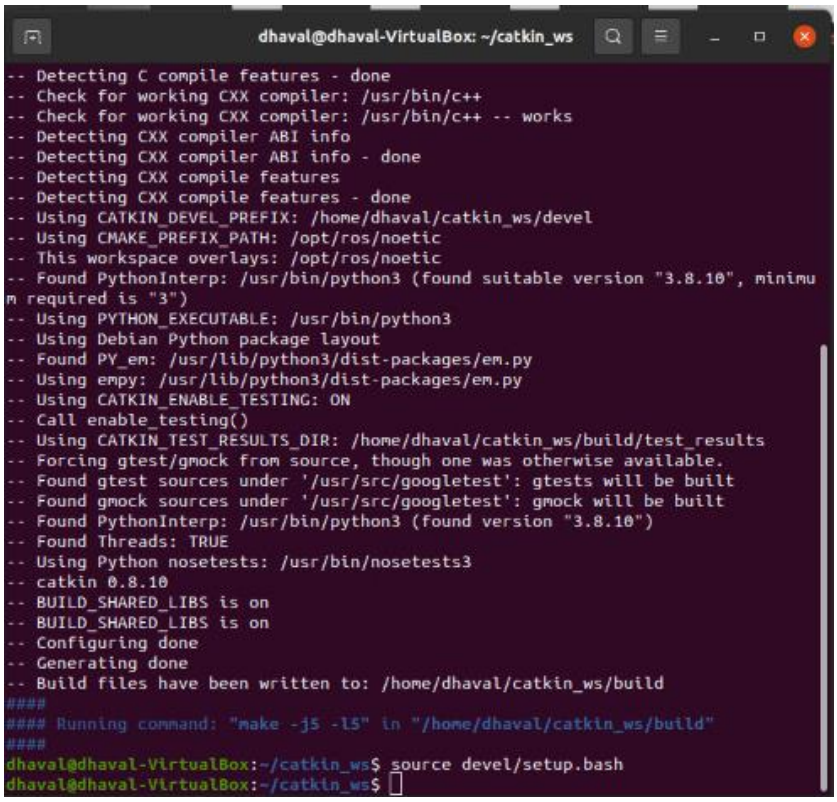
```
$ mkdir -p ~/catkin_ws/src
$ cd ~/catkin_ws/
$ catkin_make
```





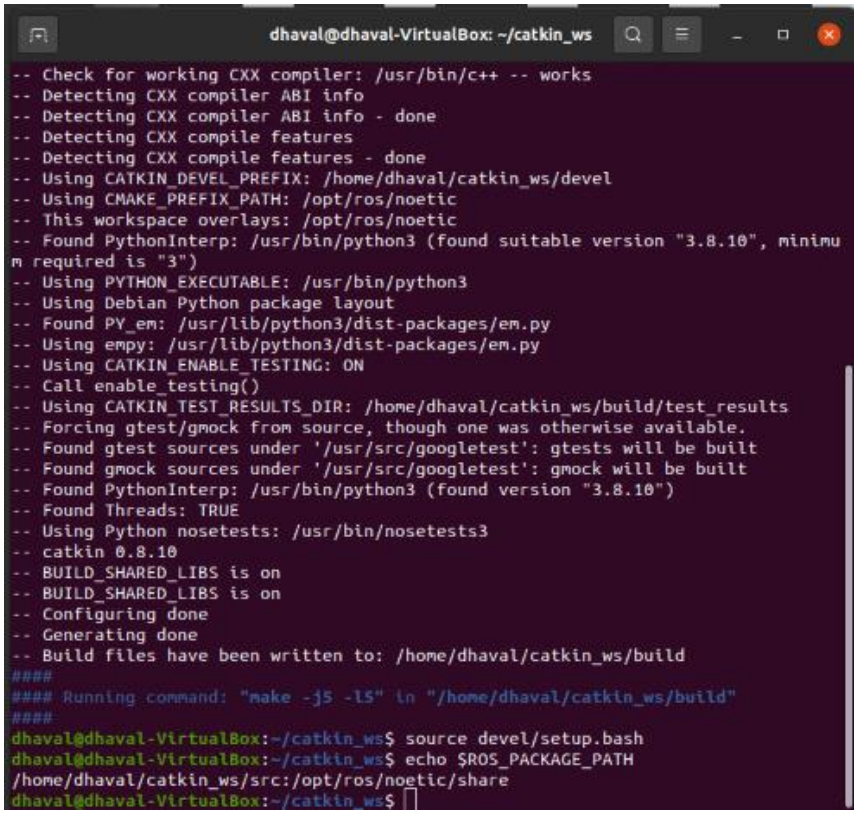
We need to setup new.*sh file and command is given below.

```
$ source devel/setup.bash
```

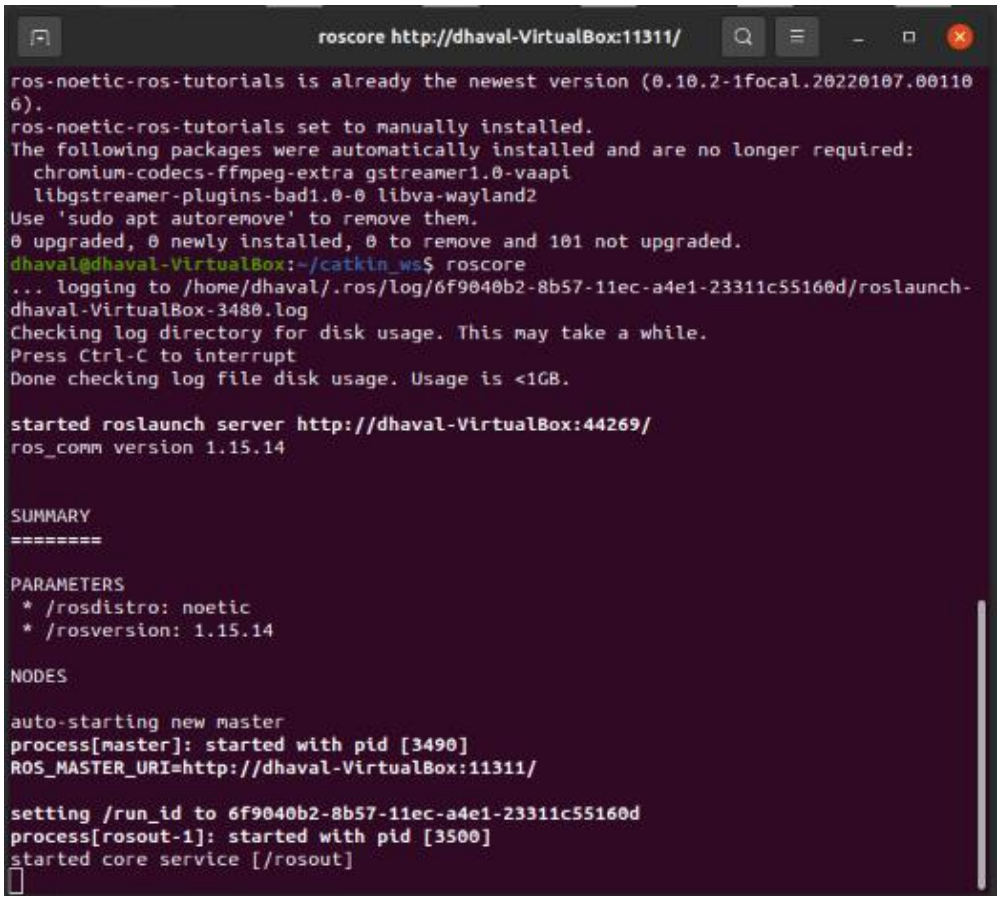


To make sure your workspace is properly overlayed by the setup script, make sure `ROS_PACKAGE_PATH` environment variable includes the directory you are in.

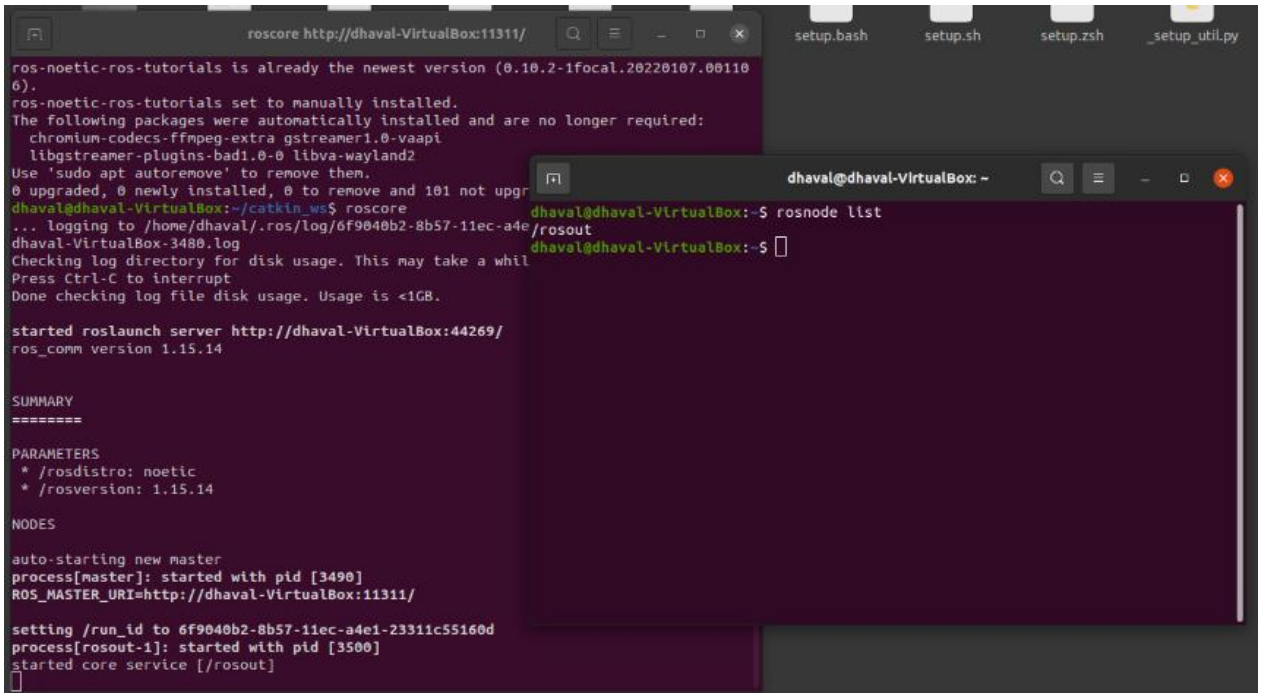
```
$ echo $ROS_PACKAGE_PATH
/home/youruser/catkin_ws/src:/opt/ros/kinetic/share
```



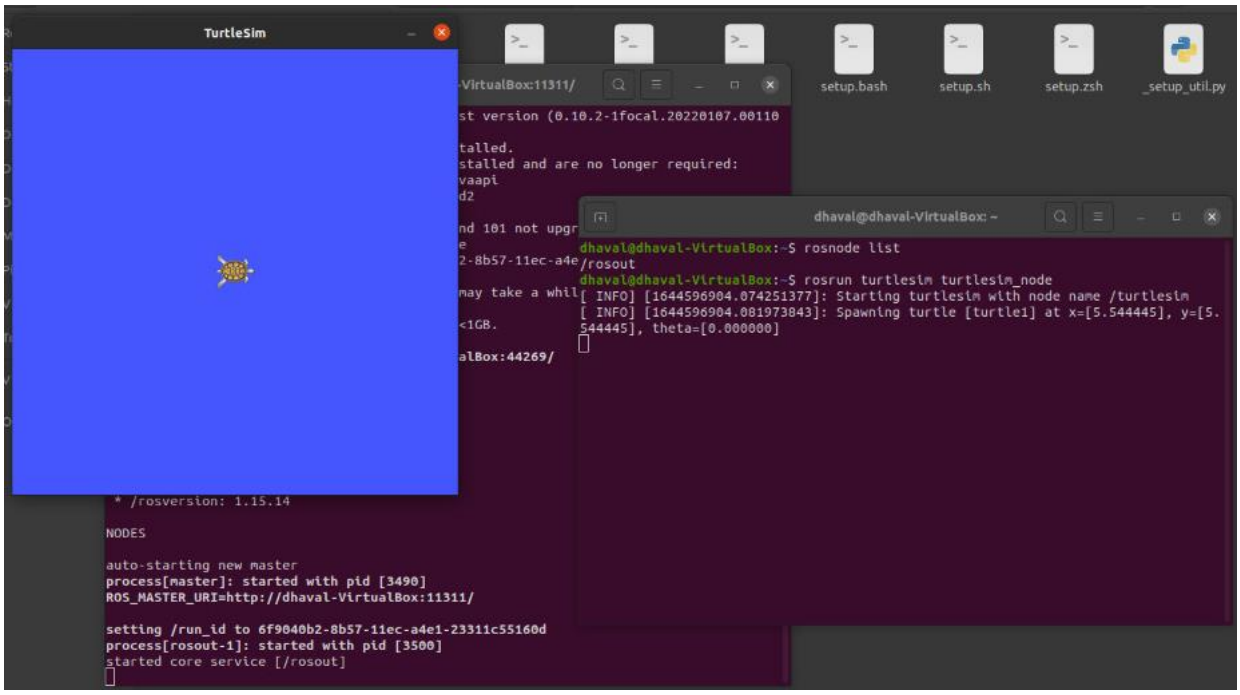
- roscore is the first thing you should run when using ROS. To run this type run `$ roscore` command.



- rosnode displays information about the ROS nodes that are currently running. The `$ rosnode list` command lists these active nodes:



- To run the turtlesim_node in the turtlesim package by using rosrun type `$ rosrun turtlesim turtlesim_node` command.



- In new terminal, type command `$ rosnode list`.